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# master
set align_gyro = DEFAULT
set gyro_lpf = OFF
set gyro_sync_denom = 1
set gyro_lowpass_type = PT1
set gyro_lowpass_hz = 90
set gyro_notch1_hz = 400
set gyro_notch1_cutoff = 300
set gyro_notch2_hz = 200
set gyro_notch2_cutoff = 100
set moron_threshold = 48
set gyro_use_32khz = OFF
set align_acc = DEFAULT
set acc_hardware = AUTO
set acc_lpf_hz = 10
set acc_trim_pitch = 0
set acc_trim_roll = 0
set baro_bustype = I2C
set baro_spi_device = 0
set baro_i2c_device = 1
set baro_i2c_address = 0
set baro_hardware = NONE
set baro_tab_size = 21
set baro_noise_lpf = 600
set baro_cf_vel = 985
set baro_cf_alt = 965
set mid_rc = 1500
set min_check = 1010
set max_check = 1990
set rssi_channel = 0
set rssi_scale = 41
set rssi_invert = OFF
set rc_interp = AUTO
set rc_interp_ch = RP
set rc_interp_int = 19
set fpv_mix_degrees = 0
set max_aux_channels = 14
set serialrx_provider = SBUS
set sbus_inversion = ON
set spektrum_sat_bind = 0
set spektrum_sat_bind_autoreset = 1
set airmode_start_throttle = 1350
set rx_min_usec = 885
set rx_max_usec = 2115
set serialrx_halfduplex = OFF
set input_filtering_mode = OFF
set blackbox_p_ratio = 0
set blackbox_device = SPIFLASH
set blackbox_on_motor_test = OFF
set blackbox_record_acc = ON
set min_throttle = 885
set max_throttle = 2000
set min_command = 885
set dshot_idle_value = 450
set use_unsynced_pwm = OFF
set motor_pwm_protocol = ONESHOT125
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set motor_pwm_rate = 480
set motor_pwm_inversion = OFF
set thr_corr_value = 0
set thr_corr_angle = 800
set failsafe_delay = 4
set failsafe_off_delay = 10
set failsafe_throttle = 1000
set failsafe_kill_switch = OFF
set failsafe_throttle_low_delay = 100
set failsafe_procedure = DROP
set align_board_roll = 0
set align_board_pitch = 0
set align_board_yaw = 0
set gimbal_mode = NORMAL
set bat_capacity = 1500
set vbat_max_cell_voltage = 43
set vbat_full_cell_voltage = 41
set vbat_min_cell_voltage = 33
set vbat_warning_cell_voltage = 35
set vbat_hysteresis = 1
set current_meter = VIRTUAL
set battery_meter = NONE
set vbat_detect_cell_voltage = 30
set use_vbat_alerts = ON
set use_cbat_alerts = OFF
set cbat_alert_percent = 10
set vbat_cutoff_percent = 100
set vbat_scale = 110
set ibata_scale = 400
set ibata_offset = 0
set ibatv_scale = 0
set ibatv_offset = 0
set beeper_inversion = ON
set beeper_od = OFF
set beeper_frequency = 0
set beeper_dshot = ON
set yaw_motors_reversed = OFF
set 3d_deadband_low = 1406
set 3d_deadband_high = 1514
set 3d_neutral = 1460
set 3d_deadband_throttle = 50
set servo_center_pulse = 1500
set servo_pwm_rate = 50
set servo_lowpass_hz = 0
set tri_unarmed_servo = ON
set channel_forwarding_start = 4
set reboot_character = 82
set serial_update_rate_hz = 100
set accxy_deadband = 40
set accz_deadband = 40
set acc_unarmedcal = ON
set imu_dcm_kp = 2500
set imu_dcm_ki = 0
set small_angle = 25
set auto_disarm_delay = 5
set disarm_kill_switch = ON
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set gyro_cal_on_first_arm = OFF
set gps_provider = NMEA
set gps_sbas_mode = AUTO
set gps_auto_config = ON
set gps_auto_baud = OFF
set gps_wp_radius = 200
set nav_controls_heading = ON
set nav_speed_min = 100
set nav_speed_max = 300
set nav_slew_rate = 30
set fixedwing_althold_reversed = OFF
set alt_hold_deadband = 40
set alt_hold_fast_change = ON
set deadband = 0
set yaw_deadband = 0
set yaw_control_reversed = OFF
set pid_process_denom = 4
set tlm_switch = OFF
set tlm_inverted = OFF
set tlm_halfduplex = ON
set frsky_default_lat = 0
set frsky_default_long = 0
set frsky_gps_format = 0
set frsky_unit = IMPERIAL
set frsky_vfas_precision = 0
set hott_alarm_int = 5
set pid_in_tlm = OFF
set report_cell_voltage = OFF
set ledstrip_visual_beeper = OFF
set sdcard_dma = OFF
set osd_units = METRIC
set osd_rssi_alarm = 20
set osd_cap_alarm = 2200
set osd_alt_alarm = 100
set osd_ah_max_pit = 20
set osd_ah_max_rol = 40
set osd_tim1 = 2560
set osd_tim2 = 2561
set osd_vbat_pos = 2092
set osd_rssi_pos = 40
set osd_tim_1_pos = 2102
set osd_tim_2_pos = 33
set osd_flymode_pos = 333
set osd_throttle_pos = 2273
set osd_vtx_channel_pos = 377
set osd_crosshairs = 2285
set osd_ah_sbar = 2286
set osd_ah_pos = 2158
set osd_current_pos = 2433
set osd_mah_drawn_pos = 2401
set osd_craft_name_pos = 2410
set osd_gps_speed_pos = 2266
set osd_gps_lon_pos = 82
set osd_gps_lat_pos = 65
set osd_gps_sats_pos = 2099
set osd_home_dir_pos = 2350

set osd_home_dist_pos = 2351
set osd_compass_bar_pos = 266
set osd_altitude_pos = 2295
set osd_pid_roll_pos = 423
set osd_pid_pitch_pos = 455
set osd_pid_yaw_pos = 487
set osd_debug_pos = 1
set osd_power_pos = 321
set osd_pidrate_profile_pos = 345
set osd_warnings_pos = 2377
set osd_avg_cell_voltage_pos = 76
set osd_pit_ang_pos = 257
set osd_rol_ang_pos = 289
set osd_battery_usage_pos = 392
set osd_disarmed_pos = 138
set osd_nheading_pos = 311
set osd_nvario_pos = 279
set osd_esc_tmp_pos = 82
set osd_esc_rpm_pos = 83
set osd_stat_max_spd = ON
set osd_stat_max_dist = OFF
set osd_stat_min_batt = ON
set osd_stat_min_rssi = ON
set osd_stat_max_curr = ON
set osd_stat_used_mah = ON
set osd_stat_max_alt = OFF
set osd_stat_bbox = ON
set osd_stat_endbatt = OFF
set osd_stat_bb_no = ON
set osd_stat_tim_1 = OFF
set osd_stat_tim_2 = ON
set task_statistics = ON
set debug_mode = NONE
set cpu_overclock = OFF
set pwr_on_arm_grace = 5
set vtx_halfduplex = ON
set vcd_video_system = 1
set vcd_h_offset = 0
set vcd_v_offset = 0
set displayport_msp_col_adjust = 0
set displayport_msp_row_adjust = 0
set displayport_max7456_col_adjust = 0
set displayport_max7456_row_adjust = 0
set displayport_max7456_inv = OFF
set displayport_max7456_blk = 0
set displayport_max7456_wht = 2
set esc_sensor_halfduplex = OFF
set led_inversion = 0
set dashboard_i2c_bus = 1
set dashboard_i2c_addr = 60
set camera_control_mode =
HARDWARE_PWM
set camera_control_ref_voltage = 330
set camera_control_key_delay = 180
set camera_control_internal_resistance = 470

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# profile
profile 0

set dterm_lowpass_type = BIQUAD
set dterm_lowpass = 100
set dterm_notch_hz = 260
set dterm_notch_cutoff = 160
set vbat_pid_gain = OFF
set pid_at_min_throttle = ON
set anti_gravity_threshold = 350
set anti_gravity_gain = 1000
set setpoint_relax_ratio = 100
set dterm_setpoint_weight = 0
set acc_limit_yaw = 100
set acc_limit = 0
set crash_dthreshold = 50
set crash_gthreshold = 400
set crash_setpoint_threshold = 350
set crash_time = 500
set crash_delay = 0
set crash_recovery_angle = 10
set crash_recovery_rate = 100
set crash_limit_yaw = 200
set crash_recovery = OFF
set itemp_windup = 50
set itemp_limit = 150
set pidsum_limit = 500
set pidsum_limit_yaw = 400
set yaw_lowpass = 0
set p_pitch = 58
set i_pitch = 50
set d_pitch = 35
set p_roll = 40
set i_roll = 40
set d_roll = 30
set p_yaw = 70
set i_yaw = 45
set d_yaw = 20
set p_alt = 50
set i_alt = 0
set d_alt = 0
set p_level = 50
set i_level = 50
set d_level = 75
set p_vel = 55
set i_vel = 55
set d_vel = 75
set level_limit = 55
set horizon_tilt_effect = 75
set horizon_tilt_expert_mode = OFF
set gps_pos_p = 15
set gps_pos_i = 0
set gps_pos_d = 0
set gps_posr_p = 34
set gps_posr_i = 14
set gps_posr_d = 53
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set gps_nav_p = 25
set gps_nav_i = 33
set gps_nav_d = 83

# rateprofile
rateprofile 0

set rc_rate = 100
set rc_rate_yaw = 100
set rc_expo = 0
set rc_expo_yaw = 0
set thr_mid = 50
set thr_expo = 0
set roll_srate = 70
set pitch_srate = 70
set yaw_srate = 70
set tpa_rate = 10
set tpa_breakpoint = 1650
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